

**AMENDMENTS TO THE SPECIFICATION**

Please amend the specification as requested below. These amendments are to correct typographical and obvious errors, and do not add new matter.

A. Please amend paragraph [0063] of the Specification as follows:

[0063] In FIG. 3A, magnetic coils ~~[[130]]~~140 and 150 are rotated by telescoping radial shaft components 120, 122 and 123. The telescoping function allows the radial shafts to shorten for to accommodate non-circular orbits. For example, the human head is typically elliptical as opposed to circular and thus energy utilization in elliptical orbits is more efficient because the electromagnets are closer to the head. In other applications, non-circular orbits could potentially be used to create more targeted stimulation, particularly in cases where one wants to avoid a sensitive area that could be damaged with serious consequences.

B. Please amend paragraph [0104] of the Specification as follows:

[0104] In one embodiment, the phantom sensor array is constructed to be as large in all dimensions as is the largest human brain. The sensors used should have sufficient uniformity and precision so as to enable accurate interpolation of magnetic field values in between their physical locations. Another embodiment of a phantom mapping the magnetic fields present within a volume is shown in FIGS. 12A-12D. FIG. 12A shows an oblique view of the assembly, ~~FIG. 11C~~ FIG. 12B the top view and FIG. 12C the side view. The phantom is comprised of a combination of a spinning disk 700 on which magnetic sensors and associated circuitry with an attached vertical-board assembly 704 with its magnetic sensors where those two boards go up and down together along threaded (worm) shaft 708. The vertical-board assembly 704 is comprised of a circuit board and the sensors 712 mounted on it.

C. Please amend paragraph [0105] of the Specification as follows:

[0105] ~~FIG. 11D~~ FIG. 12D shows the oblique view of the vertical-board assembly. The stepper motor that would reside at the base of that shaft with its associated control mechanism (not shown). The stepper motor would be driven by a combination of a controller board (e.g., the FET-3 from Stepper World like 250 in FIG. 3) and an associated control/display computer.